

Figure 2A

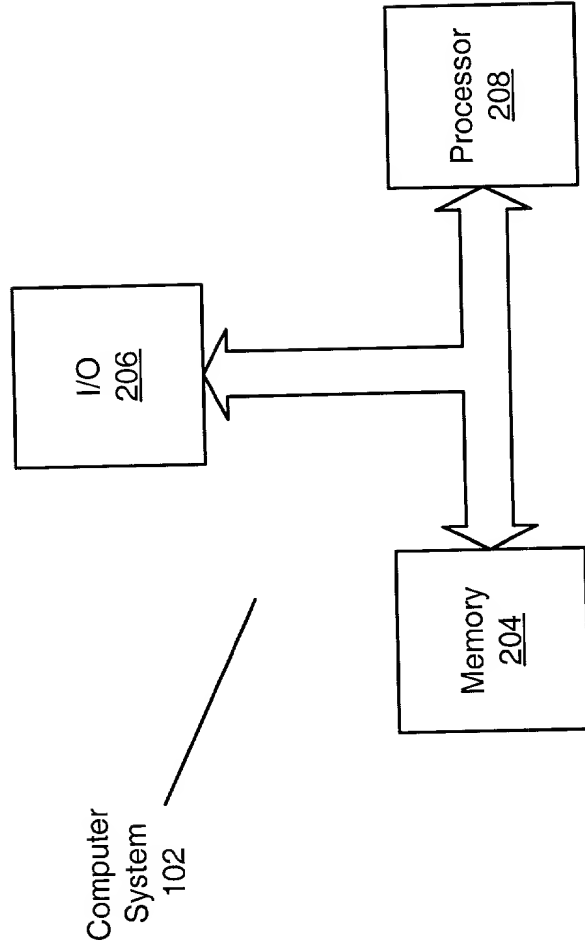


Figure 2B

FIG. 3B

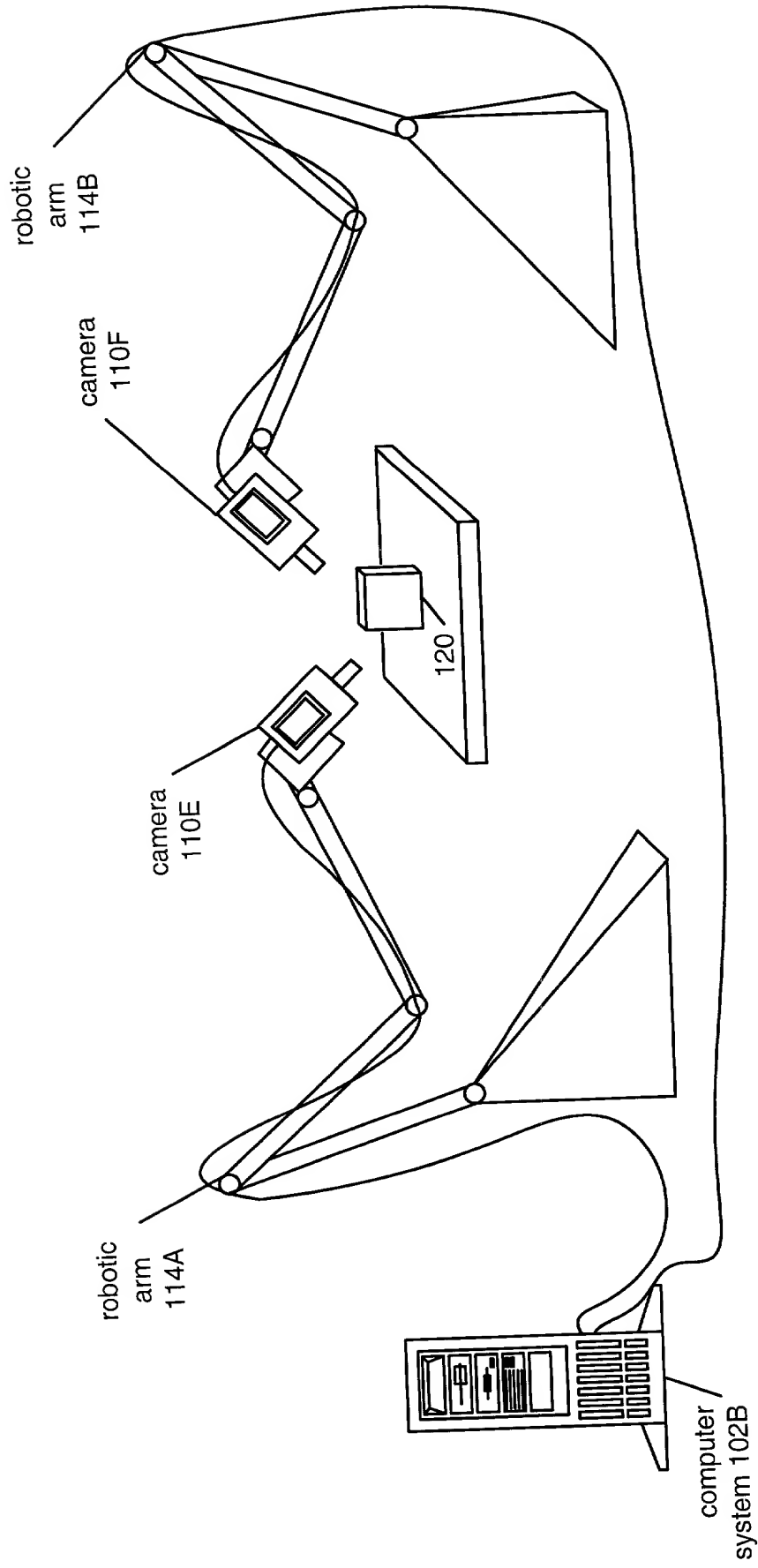


Figure 3B

FIG. 3C

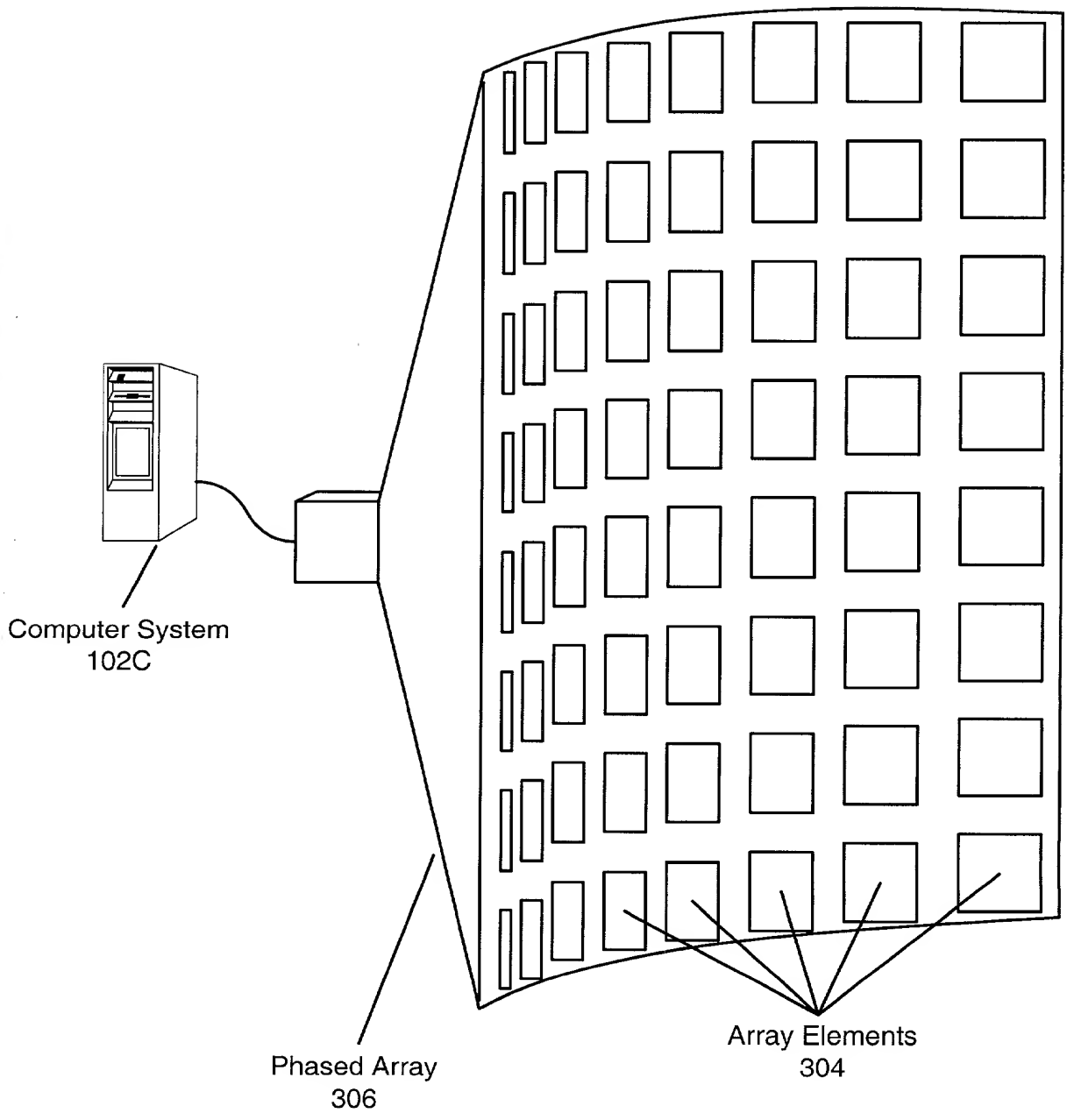


Figure 3C

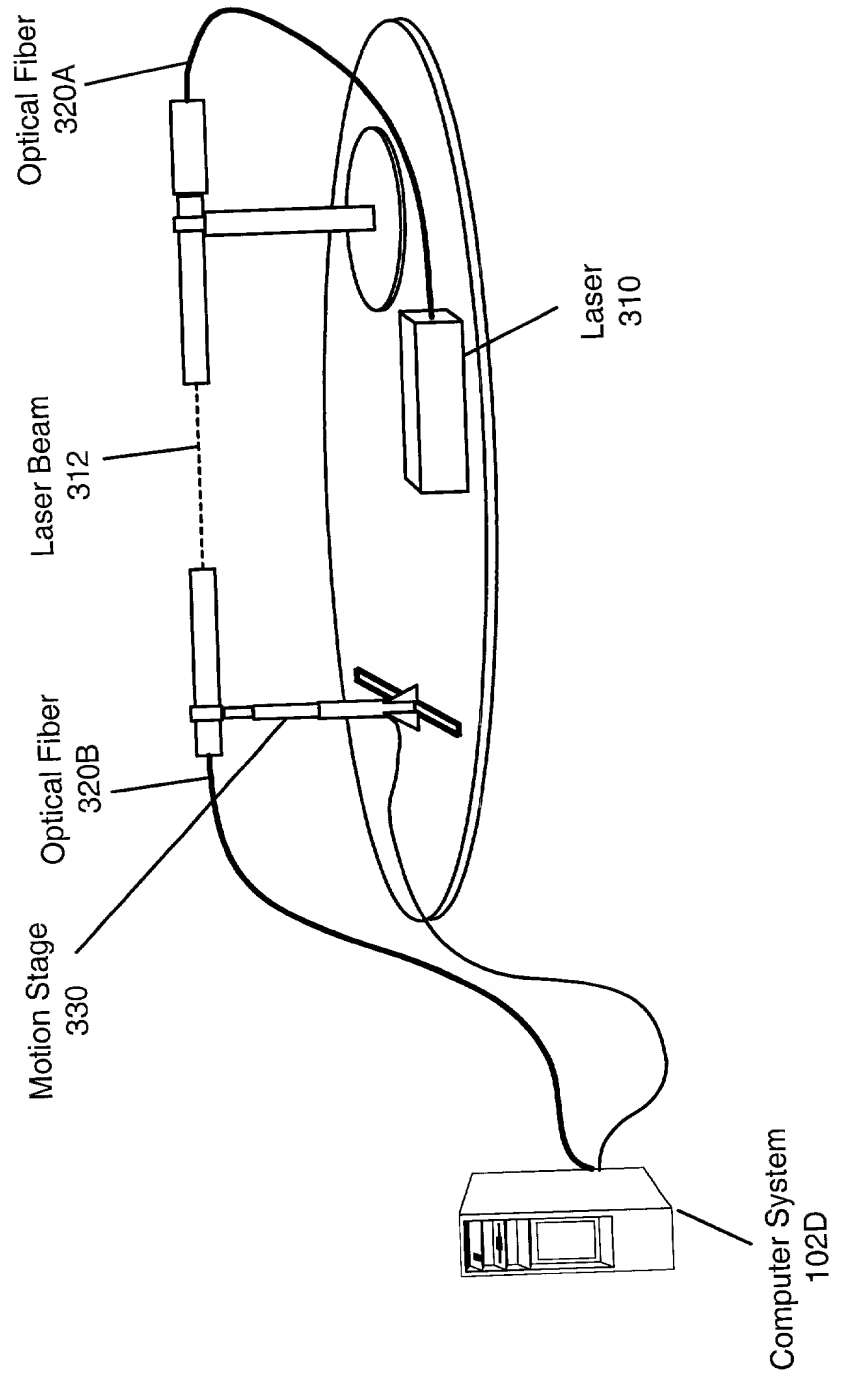
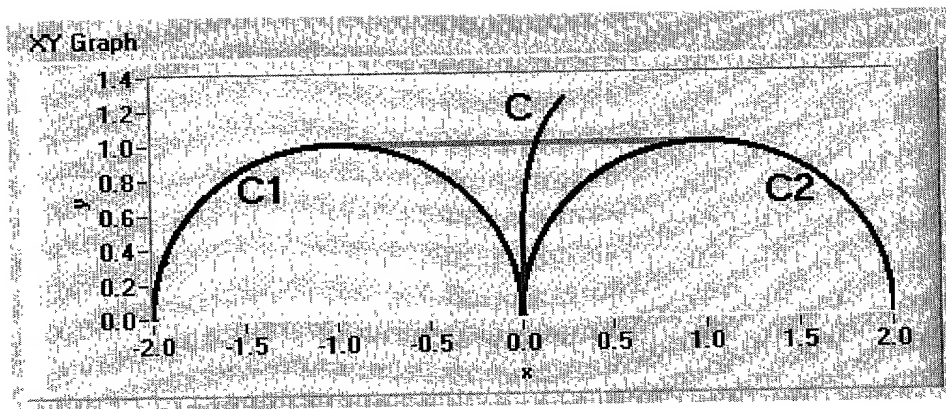
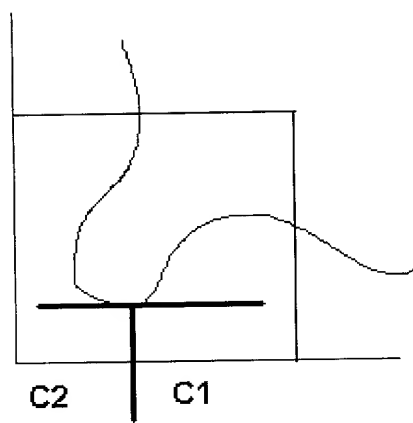


Figure 3D



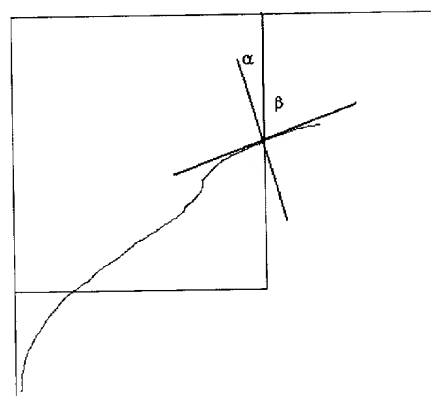
The situation of Lemma 1

Figure 4A



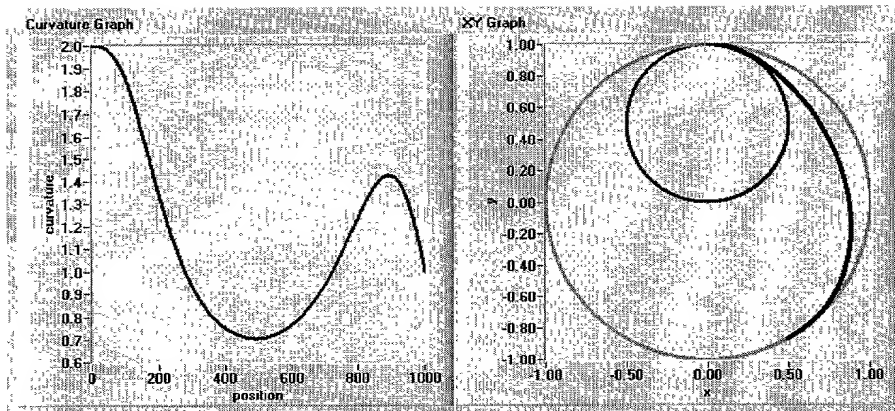
Case (A)

Figure 4B



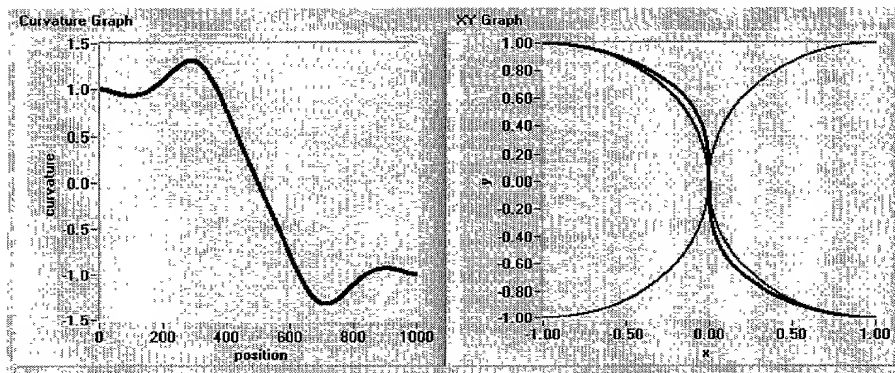
Case (B)

Figure 4C



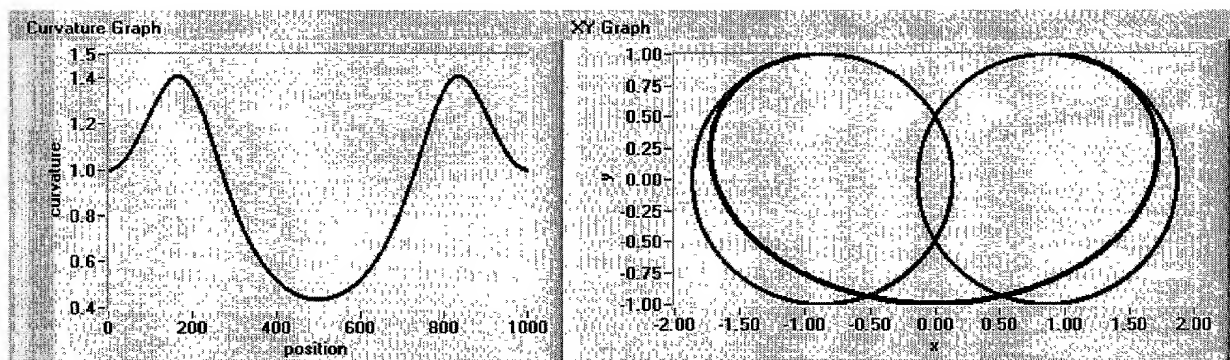
Smooth transition between two circles of different radii.

Figure 4D



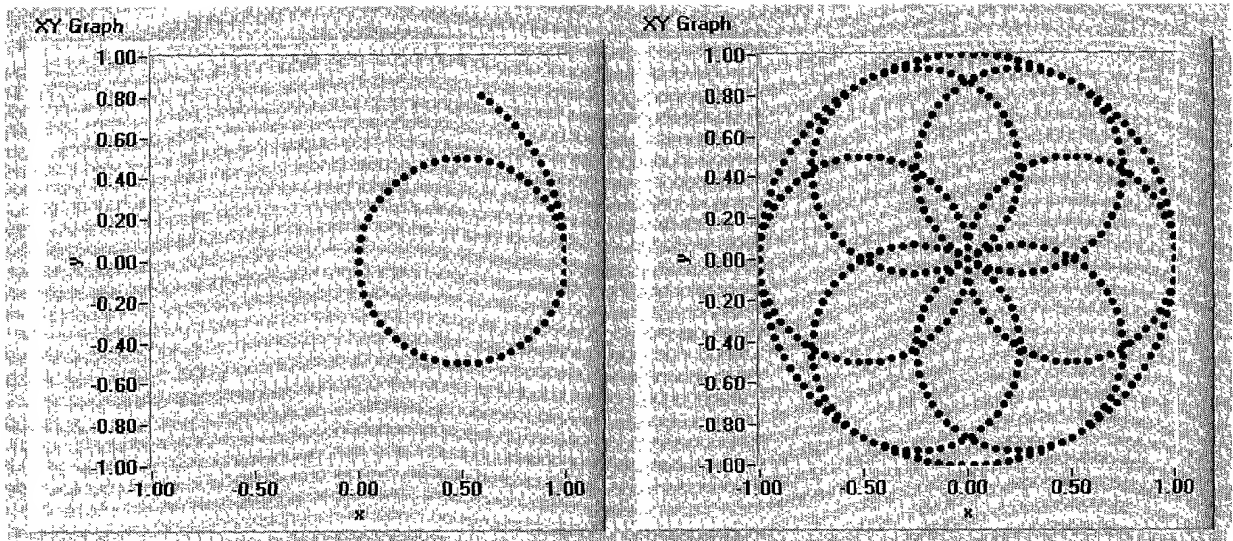
Smooth transition between two circles of same radius.

Figure 4E



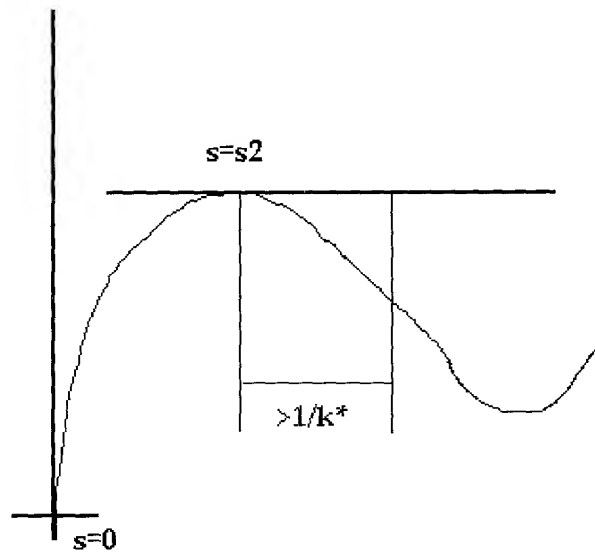
Transition between two unit circles of radius 1. The distance between the circles is $\sqrt{3}$

Figure 4F



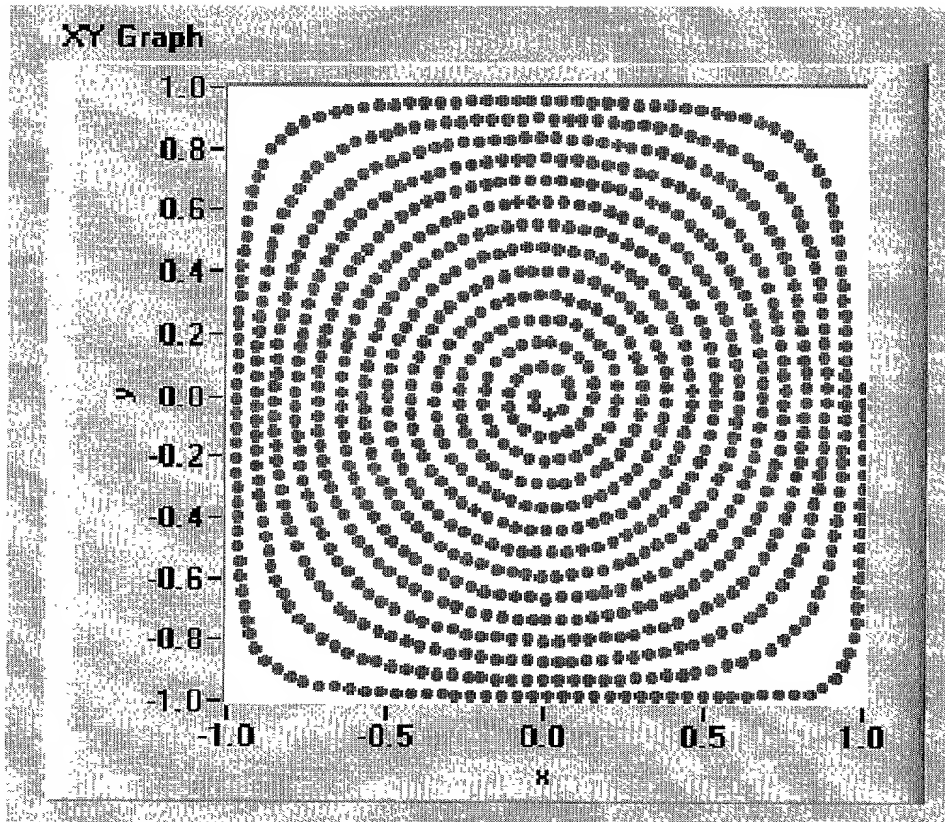
Beginning (left) and completion (right) of a scanning scheme where the curvature is below a certain value

Figure 5A



Construction of s_2 and the subsequent part of the curve

Figure 5B

[illegible]

Conformal Spiral.

Figure 6

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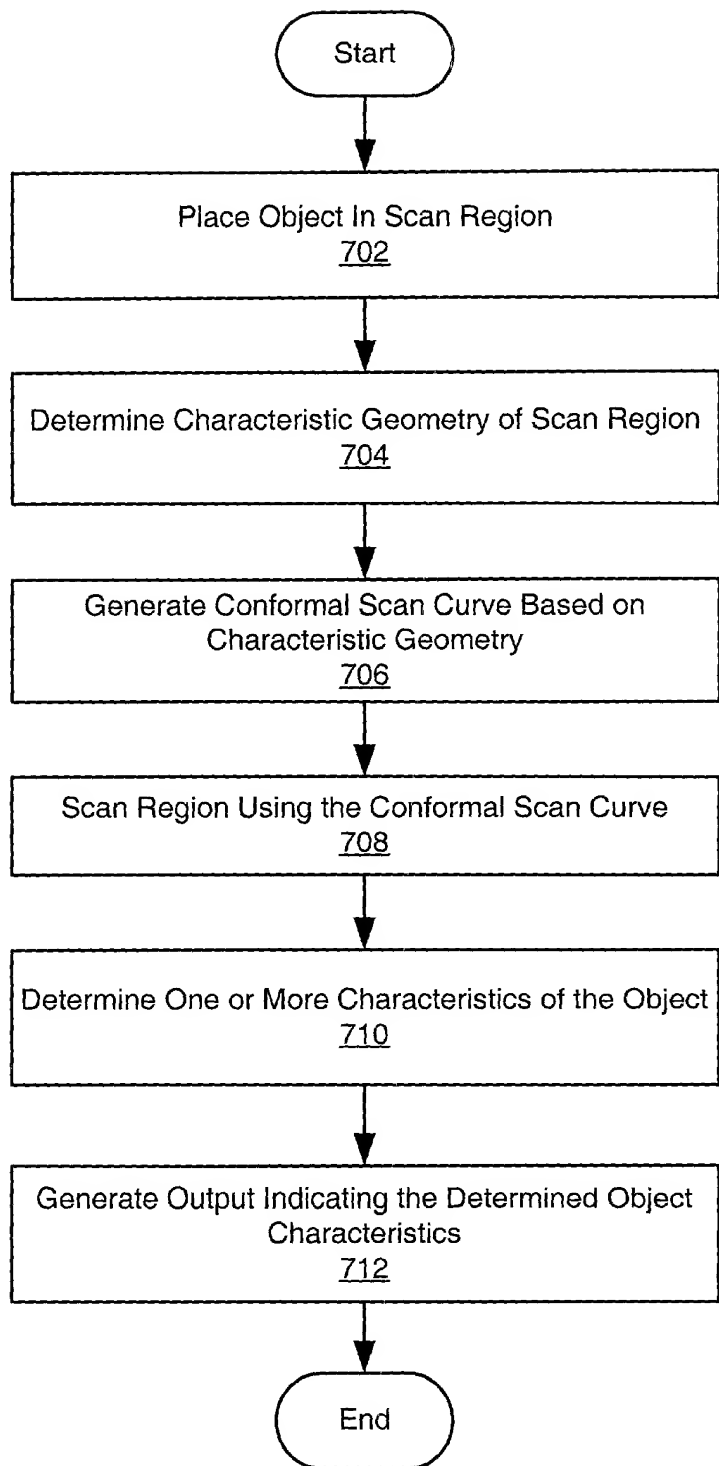
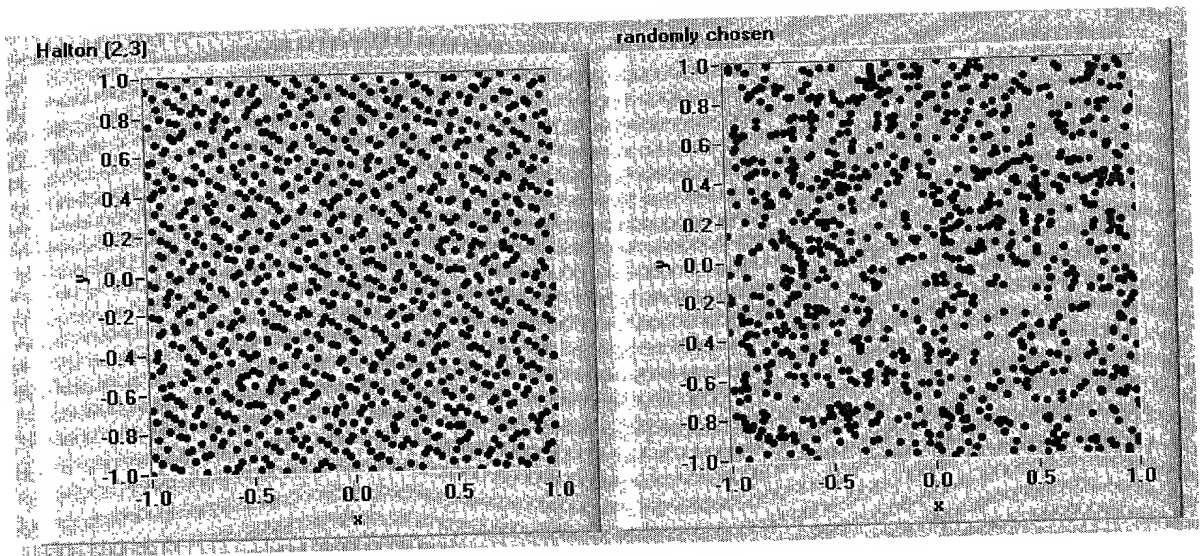
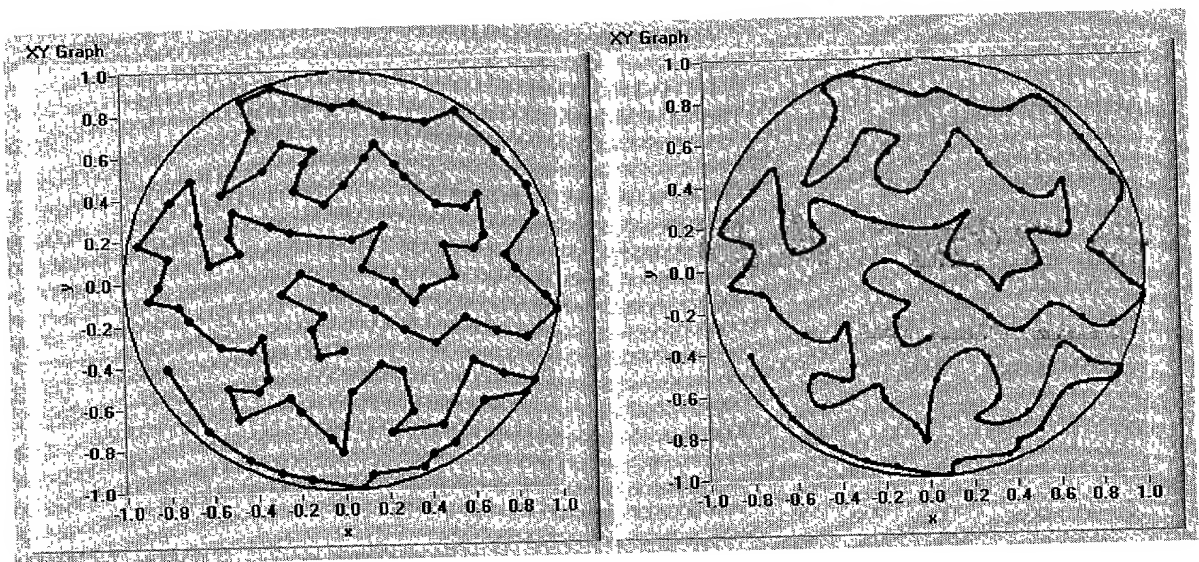


Figure 07



The first 1000 Halton points (left) and randomly chosen points (right)

Figure 8A



Original solution (left) and splined version (right).

Figure 8B

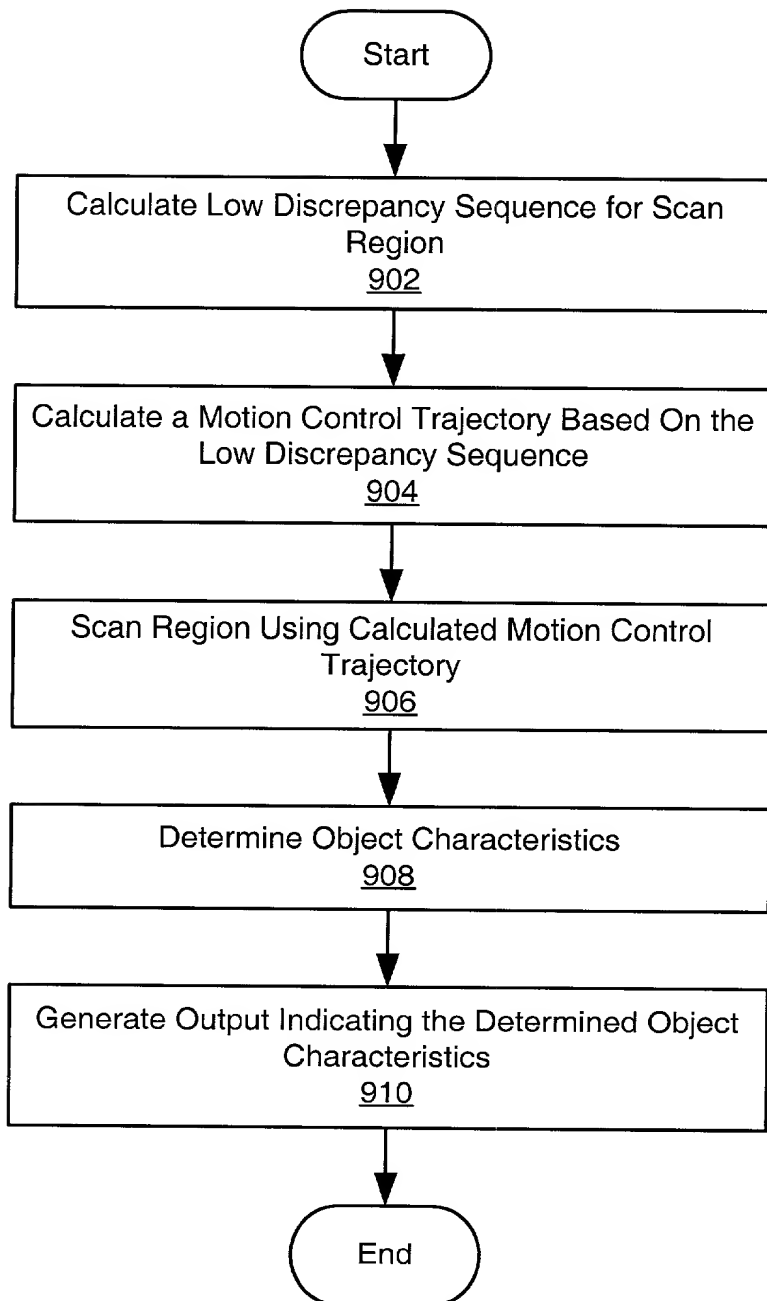
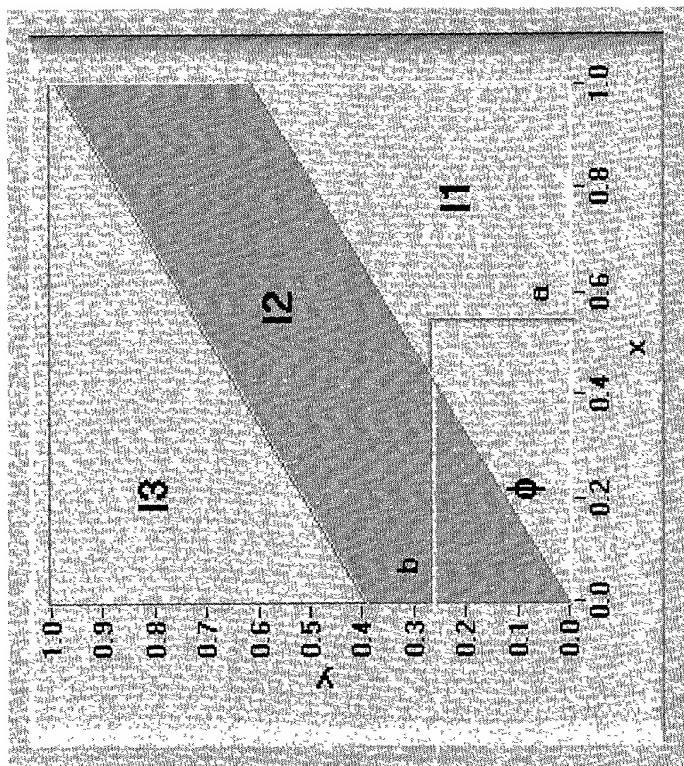


Figure 9



Definition of I_1 , I_2 , and I_3

Figure 10

BOOKS

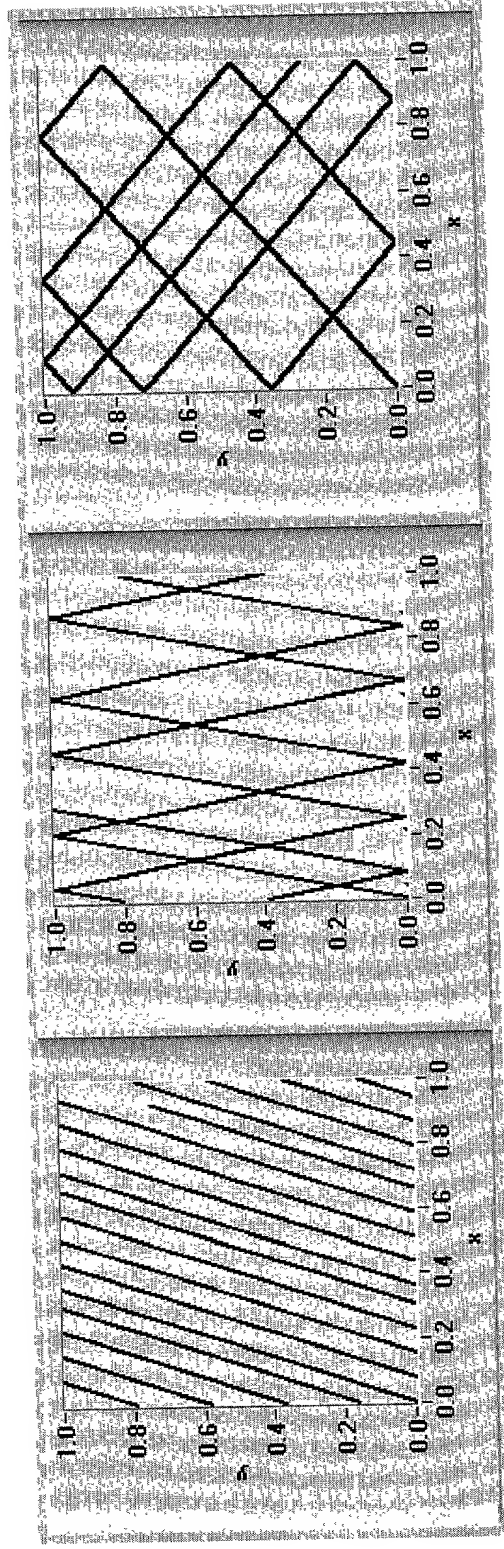
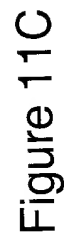
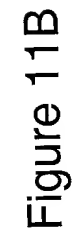


Figure 11A



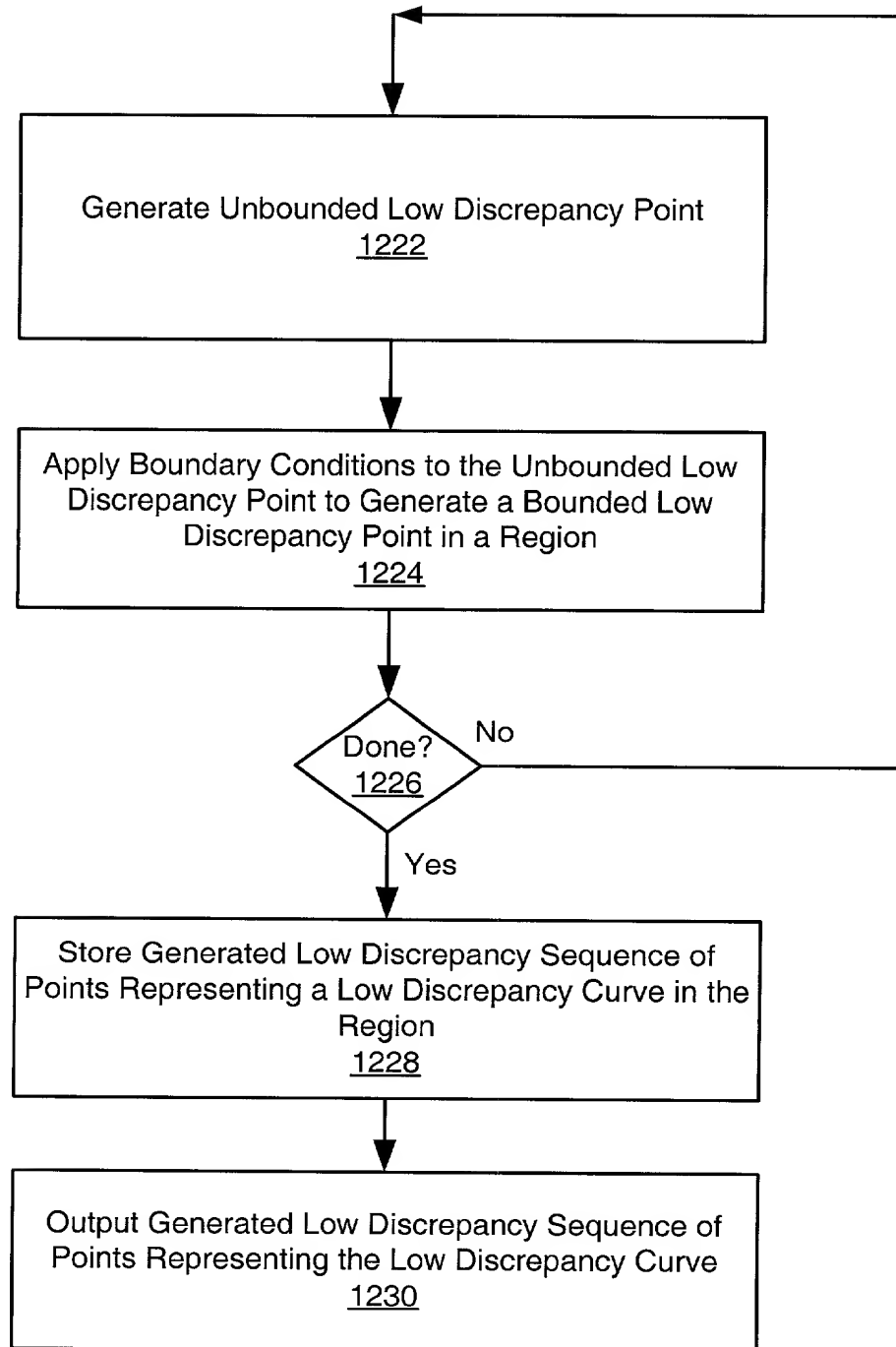
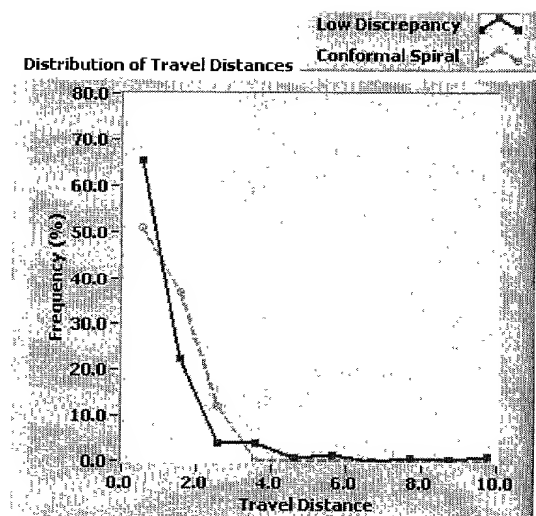


Figure 12A

Figure 13A

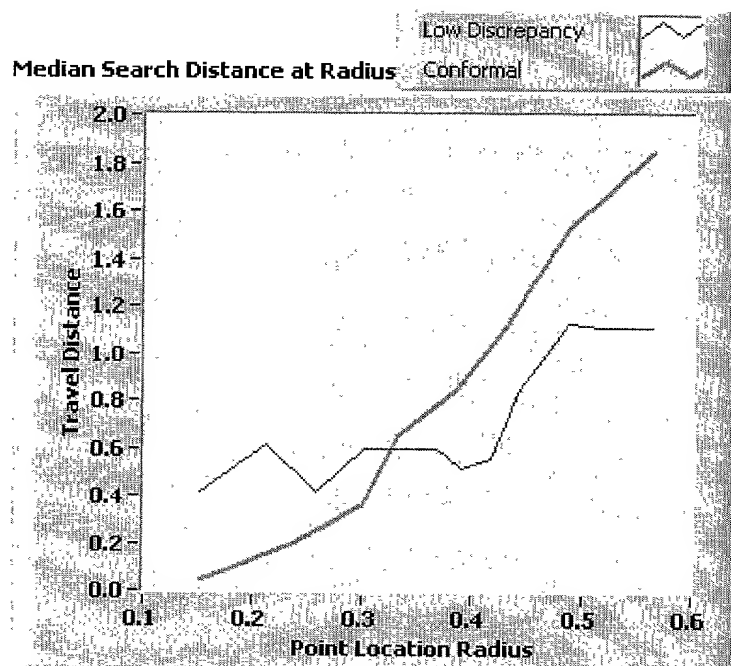


Figure 13B



Comparison of Conformal Spiral and Low Discrepancy Searching

Figure 13C



Comparison of Travel Distance for Low Discrepancy Search and Conformal Spiral Search

Figure 13D

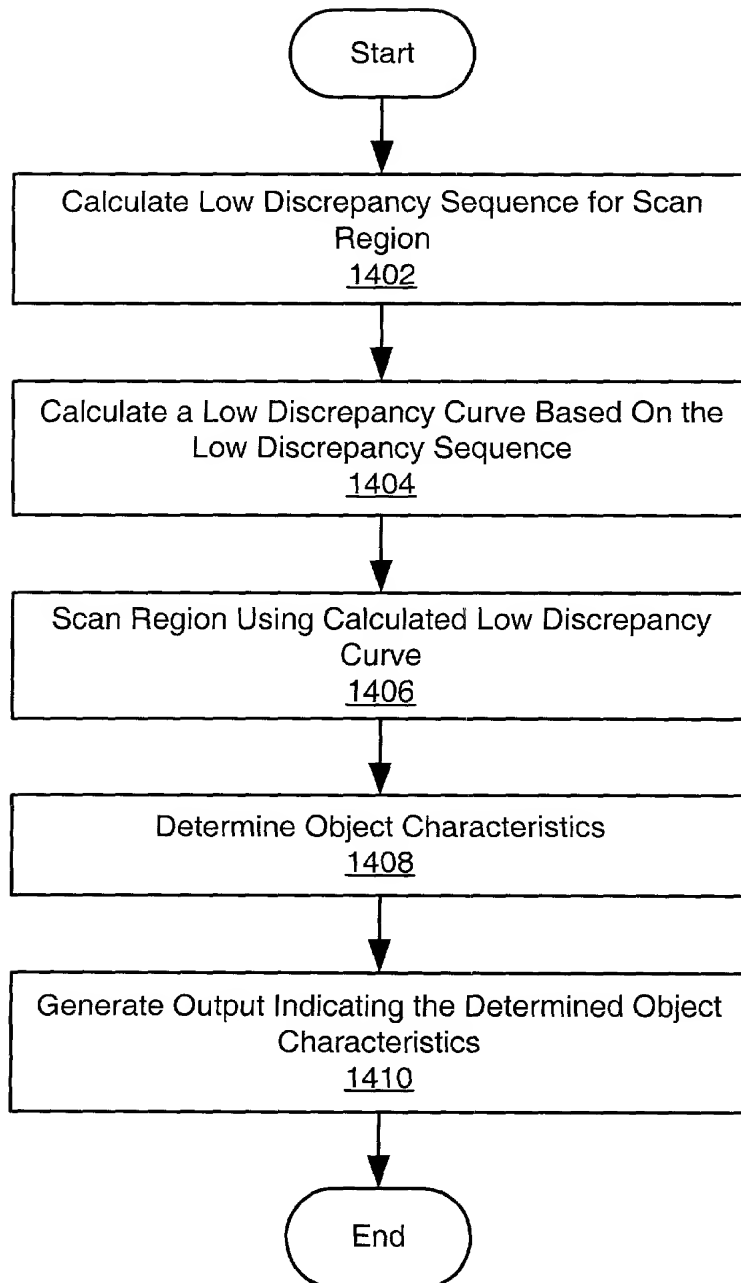
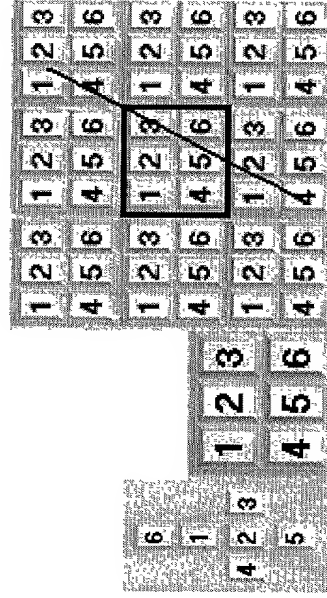
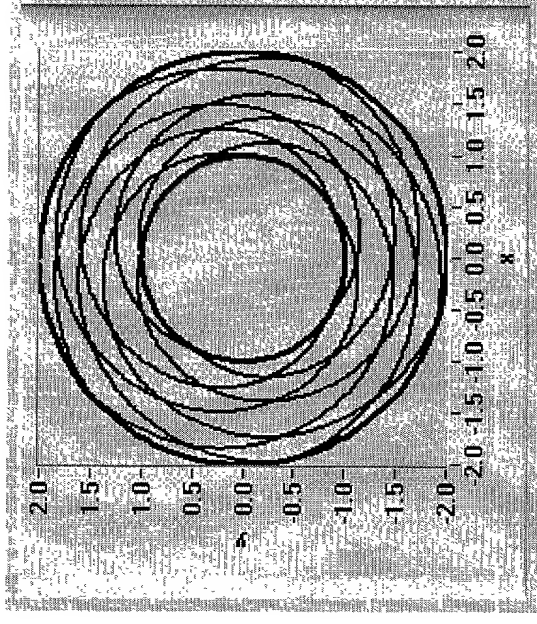


Figure 14



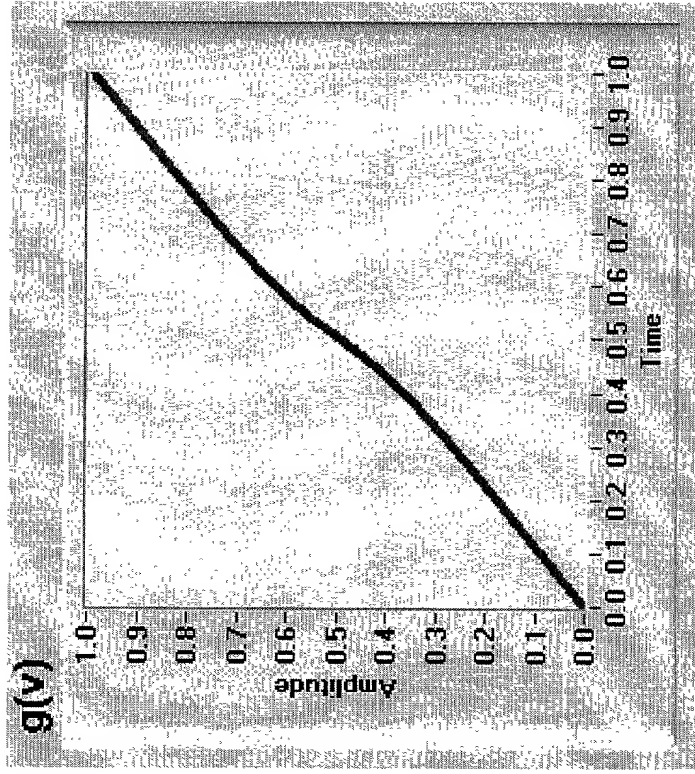
Tiling of the plane and relation to the surface of the unit cube

Figure 15A



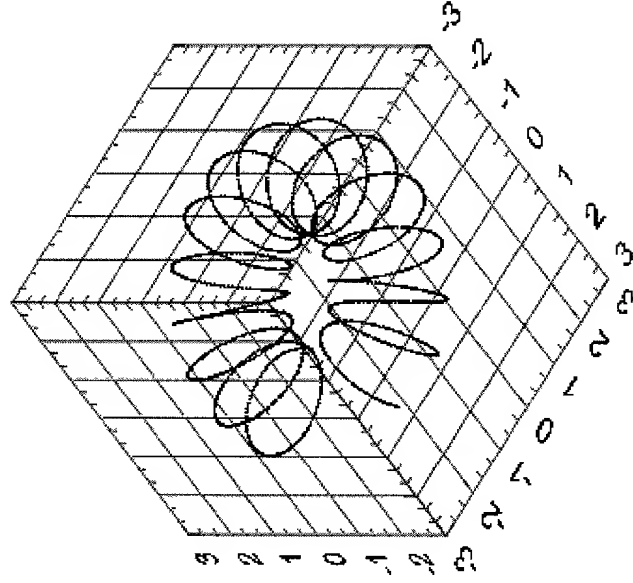
Low-discrepancy curve in a ring

Figure 15B



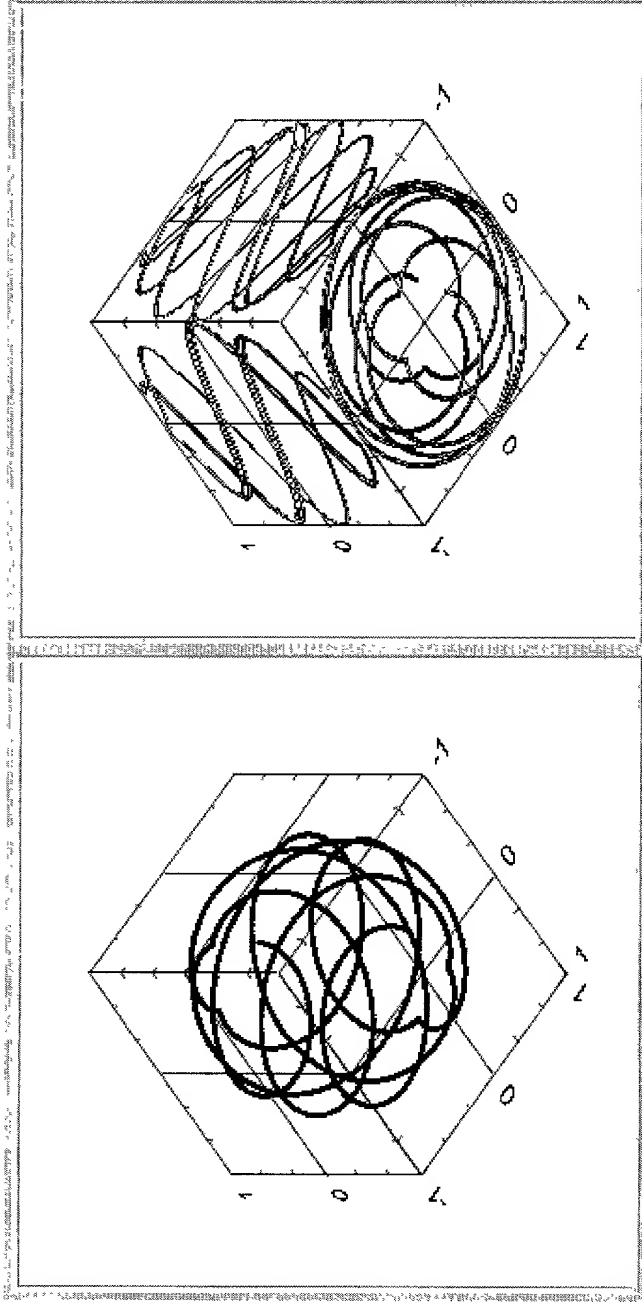
Low Discrepancy Preserving Mapping Function

Figure 15C



Low-discrepancy curve filling the surface of a torus

Figure 15D



Low-discrepancy curve on a sphere
(left) and projections (right)

Figure 16

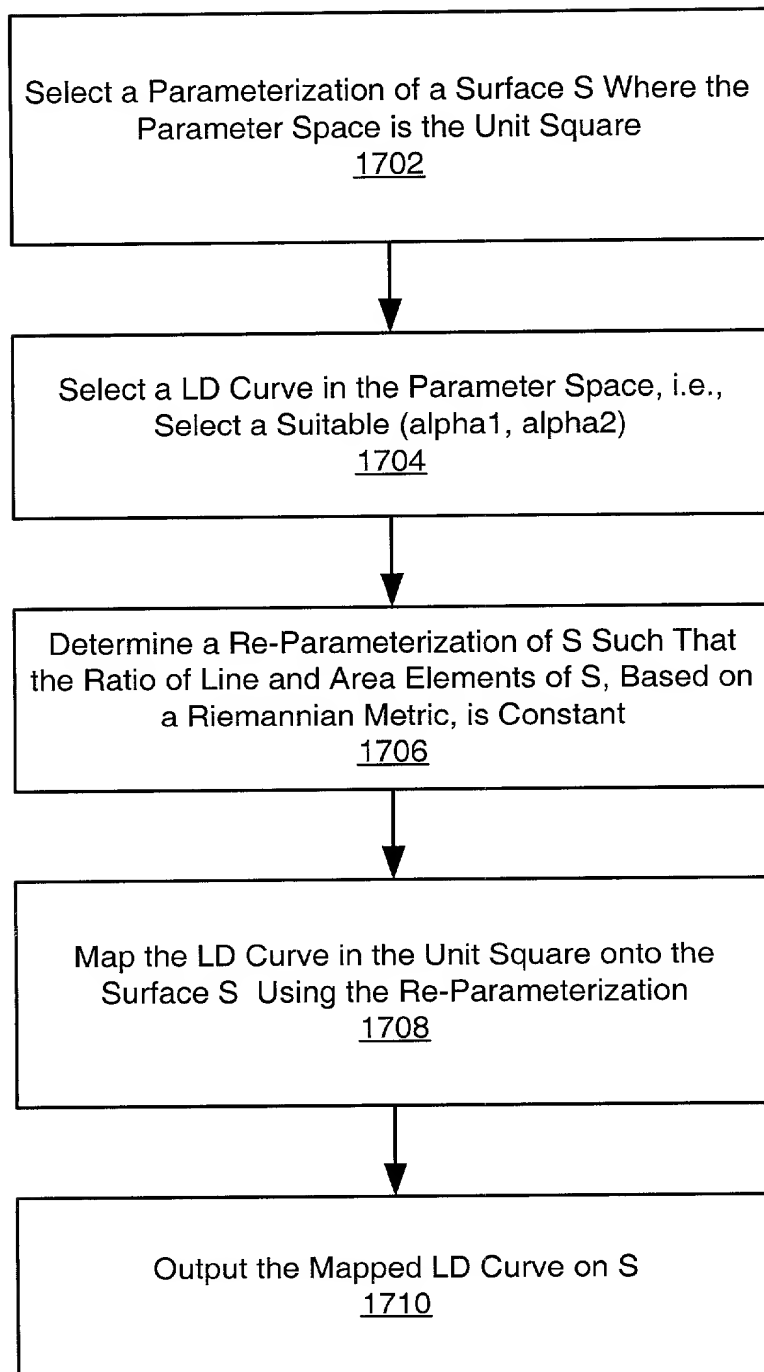
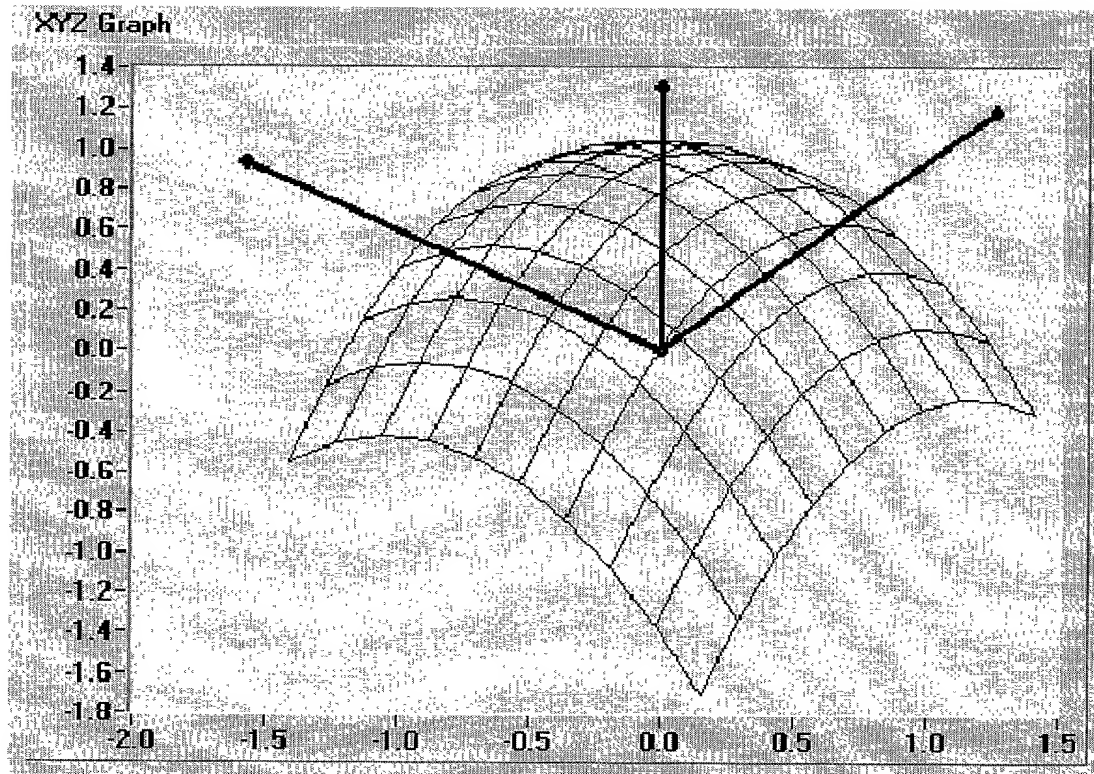


Figure 17

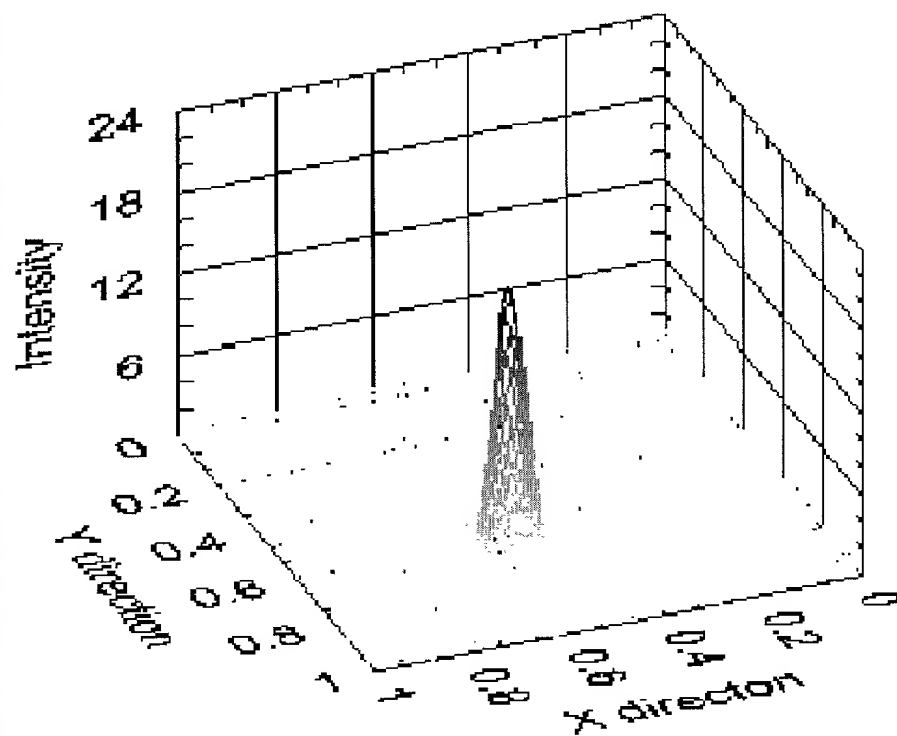


Surfaces can be scanned efficiently when the term low discrepancy sequence/curve can be generalized, e.g. based on metrics on the surface.

Figure 18

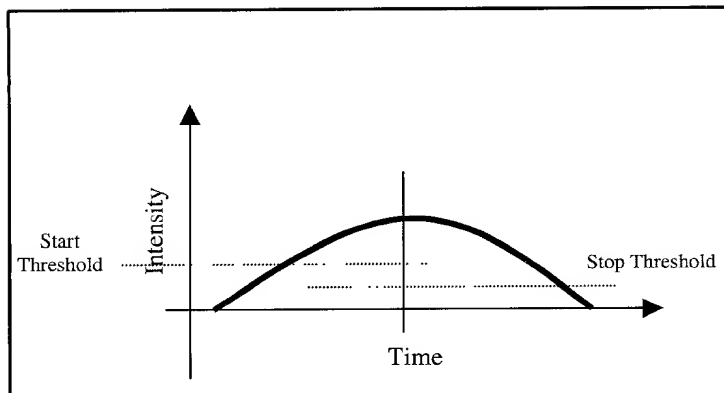
Figure 19

Intensity Field Distribution in Search Area

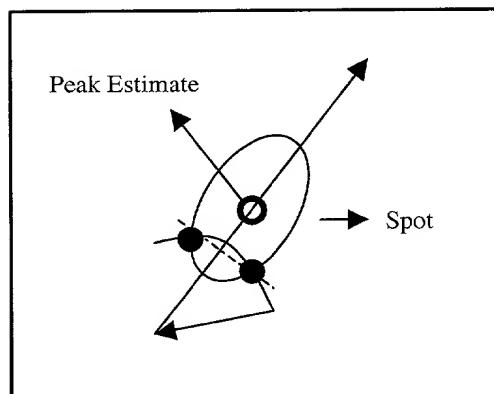


Beam intensity distribution in search area

Figure 20



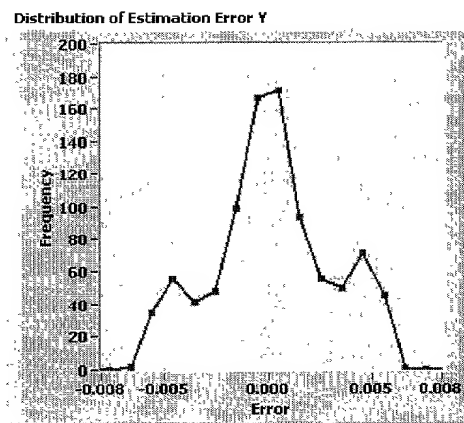
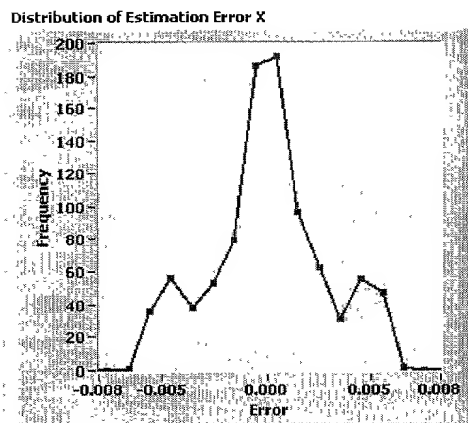
Location of the Peak



Initial Final Approach Move

Figure 21A

Figure 21B



Error distribution of the estimated peak X coordinate error (left) and Y coordinate error (right)

Figure 21C

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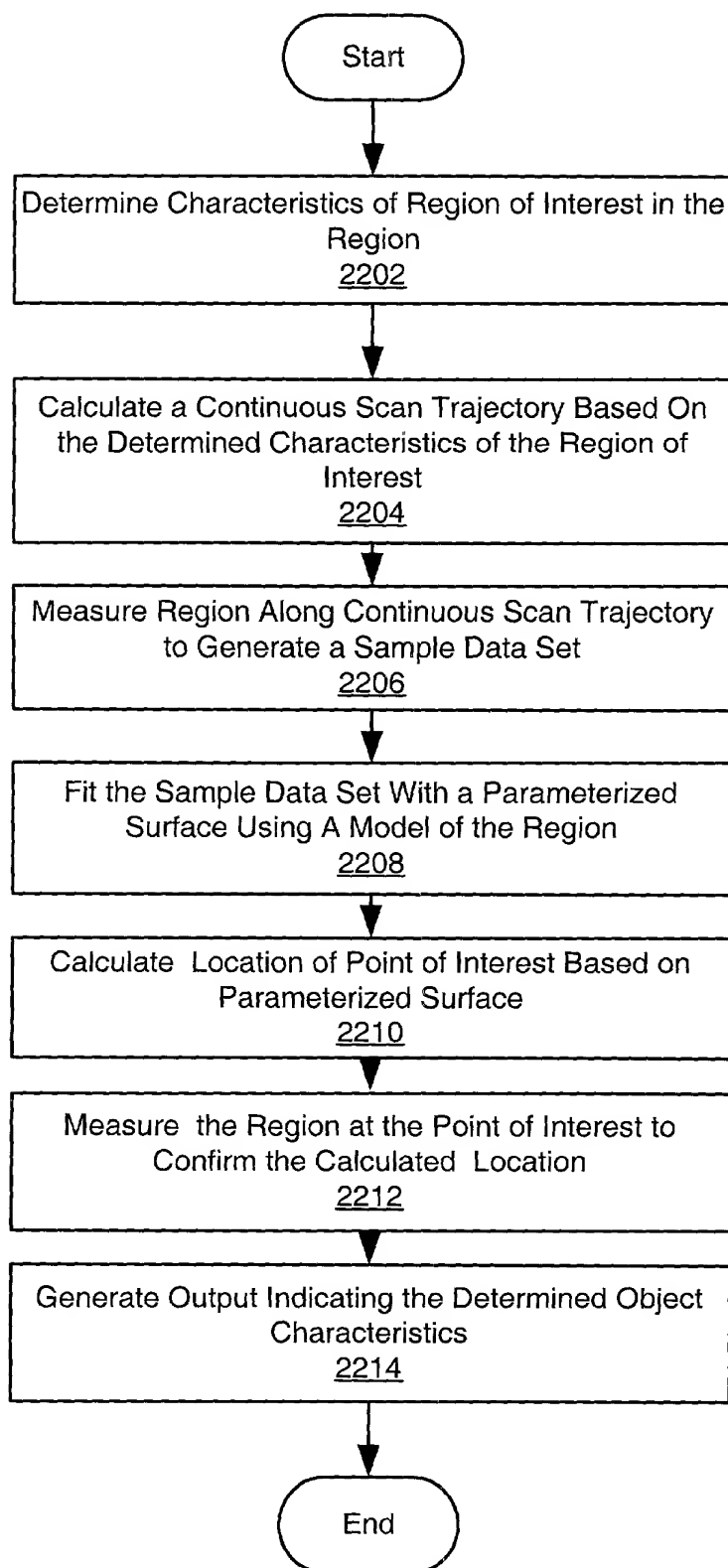


Figure 22

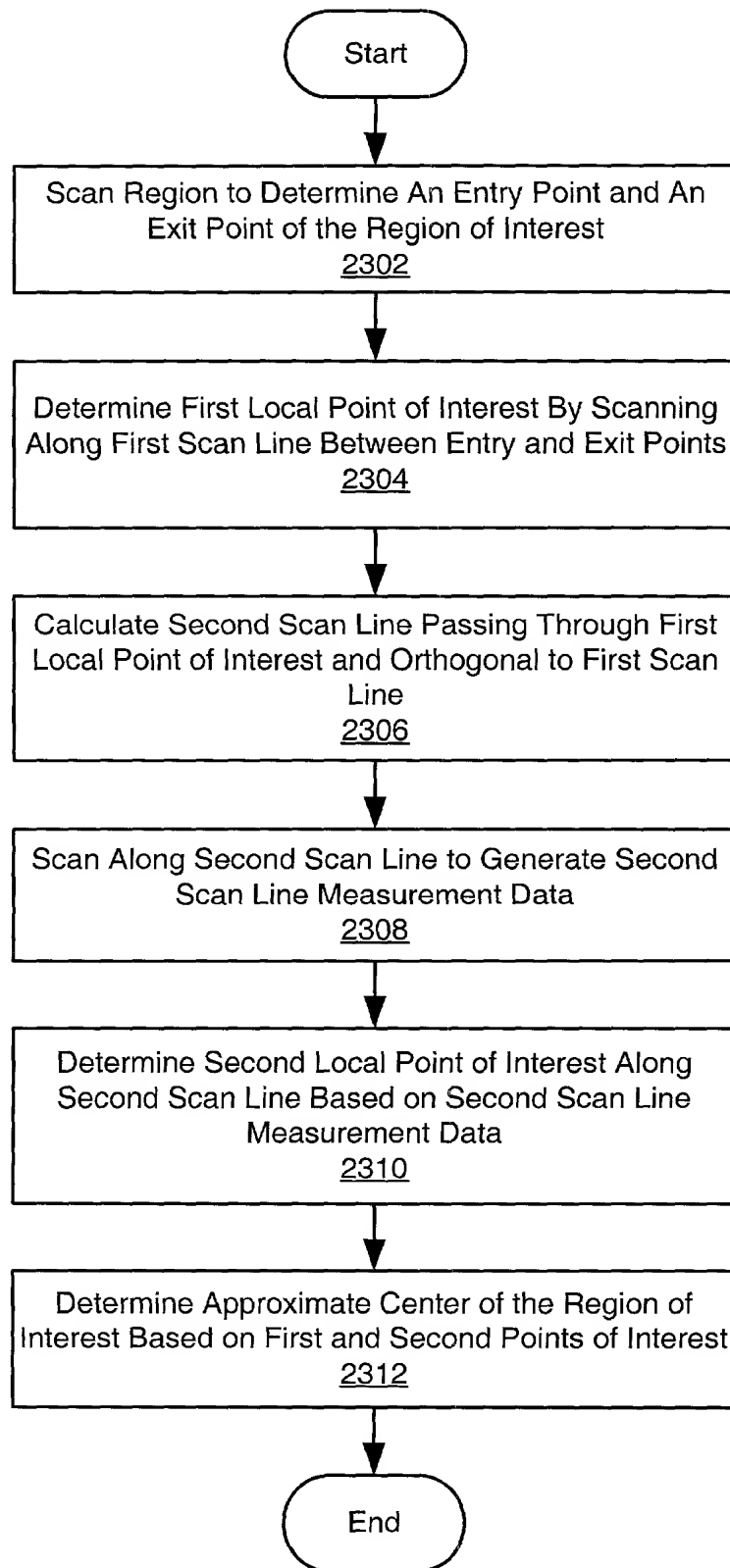
[illegible]

Figure 23